

# ABSTRACT OF THE DISCLOSURE

In steering control for individually controlling wheel steering angles  $\alpha_1$ ,  $\alpha_2$ ,  $\alpha_3$ , and  $\alpha_4$  of a vehicle in accordance with a condition equation for forming a prescribed mode, one of the condition equation variables is used as a steering command value  $S$ . In a process for changing the command value  $S$  from a value  $S_1$  to a value  $S_2$ , for transitioning the steering angles  $\alpha_1$ ,  $\alpha_2$ ,  $\alpha_3$ ,  $\alpha_4$  from values  $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S_1}$  corresponding to the steering command value  $S_1$ , to values  $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S_2}$  corresponding to the steering command value  $S_2$ , the steering angles  $\alpha_1$ ,  $\alpha_2$ ,  $\alpha_3$ ,  $\alpha_4$  are changed toward incremental transition steering angles  $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S_1 + \Delta S}$  corresponding to a steering command value  $(S_1 + \Delta S)$ , which is the steering command value  $S_1$  to which an incremental steering command value  $\Delta S$  has been added. After the steering angles  $\alpha_1$ ,  $\alpha_2$ ,  $\alpha_3$ ,  $\alpha_4$  reach their incremental transition steering angles and steering angle conformance is detected, the angles are changed toward incremental transition steering angles  $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S_1 + n\Delta S}$  corresponding to a steering command value  $(S_1 + n\Delta S)$ , which is the steering command value to which an incremental steering command value  $\Delta S$  has been added [ $n$  times] in succession. [This is repeated as many times as required] to change the steering angles  $\alpha_1$ ,  $\alpha_2$ ,  $\alpha_3$ ,  $\alpha_4$  from  $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S_1}$  to  $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S_2}$ .